

We claim:

1. A method of generating an output signal from a compensator for controlling an actuator, the method comprising:

providing to the compensator a first time-dependent
5 signal $w(t)$;

providing to the compensator a second, position-
dependent signal $f(x(t))$, where $x(t)$ is a measure of a
position of a first portion of the actuator with respect to
a second portion of the actuator;

10 modifying the first input signal as a function of the
second input signal by using a control law to produce a
third signal, $u(t)$, wherein the modifying implements the
following control law:

$$15 \quad u(t) = S(f(x(t))) + w(t)B(f(x(t))) ,$$

where $S(f(x(t)))$ represents a restoring force and
 $B(f(x(t)))$ represents a motor factor, and both are
univariate functions; and

20 outputting the third signal $u(t)$.

2. A method of generating an output signal from a compensator for controlling an electromechanical device, the method comprising:

25 providing to the compensator a first time-dependent
signal $w(t)$;

providing to the compensator a second, position-
dependent signal $f(x(t))$, where $x(t)$ is a measure of a
position of a first portion of the electromechanical device
30 with respect to a second portion of the electromechanical
device;

modifying the first input signal as a function of the
second input signal by using a control law to produce a
third signal, $u(t)$, wherein the modifying implements the
35 following control law:

$$u(t) = S(f(x(t))) + w(t)B(f(x(t))) ,$$

where $S(f(x(t)))$ represents a restoring force and
5 $B(f(x(t)))$ represents a motor factor, and both are
univariate functions; and
outputting the third signal $u(t)$.

3. A method of generating an output signal from a
10 compensator for controlling an audio reproduction system, the
method comprising:

providing to the compensator a first time-dependent
signal $w(t)$;

providing to the compensator a second, position-
15 dependent signal $f(x(t))$, where $x(t)$ is a measure of a
position of a first portion of the audio reproduction
system with respect to a second portion of the audio
reproduction system;

modifying the first input signal as a function of the
20 second input signal by using a control law to produce a
third signal, $u(t)$, wherein the modifying implements the
following control law:

$$u(t) = S(f(x(t))) + w(t)B(f(x(t))) ,$$

25 where $S(f(x(t)))$ represents a restoring force and
 $B(f(x(t)))$ represents a motor factor, and both are
univariate functions; and
outputting the third signal $u(t)$.

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4. The process according to Claim 1, wherein the function
 $S(f(x(t)))$ is derived in part from a position-dependent
restoring force acting upon an element of the actuator.

35 5. The process according to Claim 4, wherein $S(f(x(t)))$

is the subtracted version represented by equation (36a).

6. The process according to Claim 2, wherein the function $S(f(x(t)))$ is derived in part from a position-dependent
5 restoring force acting upon an element of the electromechanical device.

7. The process according to Claim 6, wherein $S(f(x(t)))$ is the subtracted version represented by equation (36a).

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8. The process according to Claim 3, wherein $S(f(x(t)))$ is derived from a ratio of the voice-coil restoring force to a motor factor of the voice-coil.

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9. The process according to Claim 8, wherein $S(f(x(t)))$ is the subtracted version represented by equation (36a).

10. The process according to Claim 1, wherein $B(f(x(t)))$ is derived from a motor factor of the actuator.

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11. The process according to Claim 10, wherein the actuator motor factor is a drive force acting upon an element of the actuator for a fiducial value of an electric current driving the actuator.

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12. The process according to Claim 2, wherein $B(f(x(t)))$ is derived from a motor factor of the electromechanical device.

13. The process according to Claim 12, wherein the motor
30 factor of the electromechanical device is the electromagnetic drive force acting upon an element of the electromechanical device for a fiducial value of the electric current driving the electromechanical device.

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14. The process according to Claim 3, wherein $B(f(x(t)))$

is derived from a motor factor of the voice coil transducer.

15. A method of generating an output signal from a compensator for controlling an actuator, the method comprising:

5 providing to the compensator a first time-dependent signal $w(t)$;

 providing to the compensator a second, position-dependent signal $f(x(t))$, where $x(t)$ is a measure of a position of a first portion of the actuator with respect to
10 a second portion of the actuator;

 modifying the first input signal as a function of the second input signal by using a control law to produce a third signal, $u(t)$, wherein the modifying implements the following control law:

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$$u(t) = w(t)B(f(x(t))),$$

 where $B(f(x(t)))$ represents a motor factor; and
 outputting the third signal $u(t)$.

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16. A method of generating an output signal from a compensator for controlling an electromechanical device, the method comprising:

25 providing to the compensator a first time-dependent signal $w(t)$;

 providing to the compensator a second, position-dependent signal $f(x(t))$, where $x(t)$ is a measure of a position of a first portion of the electromechanical device with respect to a second portion of the electromechanical
30 device;

 modifying the first input signal as a function of the second input signal by using a control law to produce a third signal, $u(t)$, wherein the modifying implements the following control law:

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$$u(t) = w(t)B(f(x(t))),$$

where $B(f(x(t)))$ represents a motor factor; and outputting the third signal $u(t)$.

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17. A method of generating an output signal from a compensator for controlling an audio reproduction system, the method comprising:

10 providing to the compensator a first time-dependent signal $w(t)$;

providing to the compensator a second, position-dependent signal $f(x(t))$, where $x(t)$ is a measure of a position of a first portion of the audio reproduction system with respect to a second portion of the audio reproduction system;

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modifying the first input signal as a function of the second input signal by using a control law to produce a third signal, $u(t)$, wherein the modifying implements the following control law:

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$$u(t) = w(t)B(f(x(t))),$$

where $B(f(x(t)))$ represents a motor factor; and outputting the third signal $u(t)$.

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18. The process according to Claim 15, wherein $B(f(x(t)))$ is derived from a motor factor of the actuator.

19. The process according to Claim 18, wherein the actuator motor factor is a drive force acting upon an element of the actuator for a fiducial value of an electric current driving the actuator.

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20. The process according to Claim 17, wherein $B(f(x(t)))$ is derived from a motor factor of the electromechanical device.

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21. The process according to Claim 20, wherein the motor factor of the electromechanical device is the electromagnetic drive force acting upon an element of the electromechanical device for a fiducial value of the electric current driving the electromechanical device.

22. The process according to Claim 17, wherein $B(f(x(t)))$ is derived from a motor factor of the voice coil transducer.

23. A method of generating an output signal from a compensator for controlling an actuator, the method comprising:

providing to the compensator a first time-dependent signal $w(t)$;

providing to the compensator a second, position-dependent signal $f(x(t))$, where $x(t)$ is a measure of a position of a first portion of the actuator with respect to a second portion of the actuator;

modifying the first input signal as a function of the second input signal by using a control law to produce a third signal, $u(t)$, wherein the modifying implements the following control law:

$$u(t) = S(f(x(t))) + w(t),$$

where $S(f(x(t)))$ represents a restoring force; and outputting the third signal $u(t)$.

24. A method of generating an output signal from a compensator for controlling an electromechanical device, the method comprising:

providing to the compensator a first time-dependent signal $w(t)$;

providing to the compensator a second, position-dependent signal $f(x(t))$, where $x(t)$ is a measure of a

position of a first portion of the electromechanical device with respect to a second portion of the electromechanical device;

5 modifying the first input signal as a function of the second input signal by using a control law to produce a third signal, $u(t)$, wherein the modifying implements the following control law:

$$u(t) = S(f(x(t))) + w(t),$$

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where $S(f(x(t)))$ represents a restoring force; and outputting the third signal $u(t)$.

25. A method of generating an output signal from a compensator for controlling an audio reproduction system, the method comprising:

15 providing to the compensator a first time-dependent signal $w(t)$;

20 providing to the compensator a second, position-dependent signal $f(x(t))$, where $x(t)$ is a measure of a position of a first portion of the audio reproduction system with respect to a second portion of the audio reproduction system;

25 modifying the first input signal as a function of the second input signal by using a control law to produce a third signal, $u(t)$, wherein the modifying implements the following control law:

$$u(t) = S(f(x(t))) + w(t),$$

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where $S(f(x(t)))$ represents a restoring force; and outputting the third signal $u(t)$.

26. The process according to Claim 23, wherein the function $S(f(x(t)))$ is derived in part from a position-dependent

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restoring force acting upon an element of the actuator.

27. The process according to Claim 26, wherein $S(f(x(t)))$ is the subtracted version represented by equation (36a).

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28. The process according to Claim 24, wherein the function $S(f(x(t)))$ is derived in part from a position-dependent restoring force acting upon an element of the electromechanical device.

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29. The process according to Claim 28, wherein $S(f(x(t)))$ is the subtracted version represented by equation (36a).

30. The process according to Claim 25, wherein $S(f(x(t)))$ is derived from a ratio of the voice-coil restoring force to a motor factor of the voice-coil.

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31. The process according to Claim 30, wherein $S(f(x(t)))$ is the subtracted version represented by equation (36a).

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32. A method of generating an output signal from a compensator for controlling an actuator, the method comprising:

providing to the compensator a first time-dependent signal, $w(t)$;

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providing to the compensator a second, position-dependent signal, $f(x(t))$, where $x(t)$ is a measure of a position of a first portion of the actuator with respect to a second portion of the actuator;

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modifying the first input signal as a function of the position-dependent signal using a control law to produce a third signal, $u(t)$, where the modifying implements the following control law:

$$u(t) = w(t) + Z(f(x(t))) * d(w(t))/dt,$$

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where $Z(f(x(t)))$ is a function $Z(.)$ of $f(x(t))$, and $d(w(t))/dt$ is the time derivative of $w(t)$; and

outputting the signal $u(t)$.

33. A method of generating an output signal from a compensator for controlling an electromechanical device, the method comprising:

providing to the compensator a first time-dependent signal, $w(t)$;

providing to the compensator a second, position-dependent signal, $f(x(t))$, where $x(t)$ is a measure of a position of a first portion of the electromechanical device with respect to a second portion of the electromechanical device;

modifying the first input signal as a function of the position-dependent signal using a control law to produce a third signal, $u(t)$, where the modifying implements the following control law:

$$u(t) = w(t) + Z(f(x(t))) * d(w(t))/dt,$$

where $Z(f(x(t)))$ is a function $Z(\cdot)$ of $f(x(t))$, and $d(w(t))/dt$ is the time derivative of $w(t)$; and

outputting the signal $u(t)$.

34. A method of generating an output signal from a compensator for controlling a voice coil audio transducer, the method comprising:

providing to the compensator a first time-dependent signal, $w(t)$;

providing to the compensator a second, position-dependent signal, $f(x(t))$, where $x(t)$ is a measure of a position of a first portion of the audio transducer with respect to a second portion of the audio transducer;

modifying the first input signal as a function of the position-dependent signal using a control law to produce a third signal, $u(t)$, where the modifying implements the following control law:

$$u(t) = w(t) + Z(f(x(t))) * d(w(t))/dt,$$

where $Z(f(x(t)))$ is a function $Z(.)$ of $f(x(t))$, and $d(w(t))/dt$ is the time derivative of $w(t)$; and outputting the signal $u(t)$.

5 35. The method according to Claim 32 where $Z(.)$ is derived from the impedance of the actuator.

36. The method according to Claim 33 where $Z(.)$ is derived from the impedance of the electromechanical device.

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37. The method according to Claim 34 where $Z(.)$ is derived from the impedance of a transducer voice coil.

38. A method of generating an output signal from a
15 compensator for controlling an actuator, the method comprising:

providing to the compensator a first time-dependent signal, $w(t)$;

providing to the compensator a second, position-dependent signal, $f(x(t))$, where $x(t)$ is a measure of a
20 position of a first portion of the actuator with respect to a second portion of the actuator;

modifying the first input signal as a function of the position-dependent signal using a control law to produce a third signal, $u(t)$, where the modifying implements the
25 following control law:

$$u(t) = w(t) + B1(f(x(t))) * d(F(f(x(t))))/dt,$$

where $B1(.)$ and $F(.)$ are functions of $f(x(t))$, and $d(F(f(x(t))))/dt$ is the time derivative of the composite function $F(f(x(t)))$; and

30 outputting a third signal based on the result $u(t)$.

39. A method of generating an output signal from a compensator for controlling an electromechanical device, the method comprising:

35 providing to the compensator a first time-dependent

signal, $w(t)$;

providing to the compensator a second, position-dependent signal, $f(x(t))$, where $x(t)$ is a measure of a position of a first portion of the electromechanical device with respect to a second portion of the electromechanical device;

modifying the first input signal as a function of the position-dependent signal using a control law to produce a third signal, $u(t)$, where the modifying implements the following control law:

$$u(t) = w(t) + B1(f(x(t))) * d(F(f(x(t))))/dt,$$

where $B1(.)$ and $F(.)$ are functions of $f(x(t))$, and $d(F(f(x(t))))/dt$ is the time derivative of the composite function $F(f(x(t)))$; and

outputting a third signal based on the result $u(t)$.

40. A method of generating an output signal from a compensator for controlling a voice coil audio transducer, the method comprising:

providing to the compensator a first time-dependent signal, $w(t)$;

providing to the compensator a second, position-dependent signal, $f(x(t))$, where $x(t)$ is a measure of a position of a first portion of the audio transducer with respect to a second portion of the audio transducer;

modifying the first input signal as a function of the position-dependent signal using a control law to produce a third signal, $u(t)$, where the modifying implements the following control law:

$$u(t) = w(t) + B1(f(x(t))) * d(F(f(x(t))))/dt,$$

where $B1(.)$ and $F(.)$ are functions of $f(x(t))$, and $d(F(f(x(t))))/dt$ is the time derivative of the composite function $F(f(x(t)))$; and

outputting a third signal based on the result $u(t)$.

41. The method according to Claim 38 wherein $B1(f(x(t)))$ is derived from a motor factor of the actuator, and $F(f(x(t)))$ is an estimate of a relative position of a first portion of the actuator with respect to a second portion of the actuator, and
5 where the estimate is derived from a position-indicator actuator generalized coordinate $f(x(t))$.

42. The method according to Claim 38, wherein the function $B1(.)$ is comprised of:
10 a first portion derived from a non-linear motor factor of the actuator;
a second portion which represents an adjustable, approximately linear damping; and
wherein the resultant function, $B1(.)$ is comprised of
15 the second portion subtracted from the first portion.

43. The method according to Claim 39, wherein $B1(f(x(t)))$ is derived from a motor factor of the electromechanical device; wherein $F(f(x(t)))$ is an estimate of a relative position of a
20 first portion of the electromechanical device with respect to a second portion of the electromechanical device derived from a position-indicator generalized coordinate $f(x(t))$ of the electromechanical device; and further wherein $x(t)$ is said relative position.

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44. The method according to Claim 39, wherein the function $B1(.)$ is comprised of:
a first portion derived from a non-linear motor factor of the actuator;
30 a second portion which represents an adjustable, approximately linear damping; and
wherein the resultant function, $B1(.)$ is comprised of the second portion subtracted from the first portion.

35 45. The method according to Claim 40, wherein the voice

coil audio transducer comprises a voice coil and an associated diaphragm, wherein $B1(f(x(t)))$ is derived from a motor factor of the voice coil audio transducer and $F(f(x(t)))$ is an estimate of position of the coil and associated diaphragm derived from a position-indicator generalized coordinate $f(x(t))$ of the audio transducer, and wherein $x(t)$ is the position of the coil and associated diaphragm with respect to another portion of the transducer.

- 10 46. The method according to claim 40, where the function $B1(.)$ comprises:
- a first portion derived from a non-linear motor factor of the actuator;
 - a second portion which represents an adjustable,
 - 15 approximately linear damping; and
 - wherein the resultant function, $B1(.)$ is comprised of the second portion subtracted from the first portion.

- 20 47. The method according to claim 46, wherein the second portion is derived from the equation:
- $$p * BL(0) * BL(0) / BL(f(x(t))),$$
- where p is an adjustable constant;
- where $BL(0)$ is a motor factor of the voice coil and associated diaphragm when no drive signal is applied to the voice coil; and
- 25 $BL(f(x(t)))$ is a position-dependent nonlinear motor factor.

- 30 48. The method according to claim 34, wherein the first time-dependent signal $w(t)$ is an audio program transducer input.

49. The method according to claim 40, wherein the first time-dependent signal $w(t)$ is an audio program transducer input.

- 35 50. A compensator for generating an actuator control

signal, the compensator comprising circuitry for:

receiving a first time-dependent signal $w(t)$;

receiving a second, position-dependent signal $f(x(t))$,

where $x(t)$ is a measure of a position of a first portion of
the actuator with respect to a second portion of the
actuator; and

modifying the first input signal as a function of the
second input signal by using a control law to produce the
actuator control signal, $u(t)$, wherein the modifying
implements the following control law:

$$u(t) = S(f(x(t))) + w(t)B(f(x(t))) ,$$

where $S(f(x(t)))$ represents a restoring force and
 $B(f(x(t)))$ represents a motor factor, and both are
univariate functions.

51. A compensator for generating a control signal for an
electromechanical device, the compensator comprising circuitry
for:

receiving a first time-dependent signal $w(t)$;

receiving a second, position-dependent signal $f(x(t))$,
where $x(t)$ is a measure of a position of a first portion of
the electromechanical device with respect to a second
portion of the electromechanical device; and

modifying the first input signal as a function of the
second input signal by using a control law to produce the
control signal, $u(t)$, wherein the modifying implements the
following control law:

$$u(t) = S(f(x(t))) + w(t)B(f(x(t))) ,$$

where $S(f(x(t)))$ represents a restoring force and
 $B(f(x(t)))$ represents a motor factor, and both are
univariate functions.

52. A compensator for generating a control signal for an audio reproduction system, the compensator comprising circuitry for:

- 5 receiving a first time-dependent signal $w(t)$;
 receiving a second, position-dependent signal $f(x(t))$,
where $x(t)$ is a measure of a position of a first portion of
the audio reproduction system with respect to a second
portion of the audio reproduction system; and
10 modifying the first input signal as a function of the
second input signal by using a control law to produce the
control signal, $u(t)$, wherein the modifying implements the
following control law:

15
$$u(t) = S(f(x(t))) + w(t)B(f(x(t))) ,$$

 where $S(f(x(t)))$ represents a restoring force and
 $B(f(x(t)))$ represents a motor factor, and both are
univariate functions.

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53. The compensator according to Claim 50, wherein the
circuitry modifying the first input signal as a function of the
second input signal derives the function $S(f(x(t)))$ at least in
part from a position-dependent restoring force acting upon an
25 element of the actuator.

54. The compensator according to Claim 53, wherein the
circuitry deriving $S(f(x(t)))$ implements the subtracted version
represented by equation (36a).

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55. The compensator according to Claim 51, wherein the
circuitry modifying the first input signal as a function of the
second input signal derives the function $S(f(x(t)))$ at least in
part from a position-dependent restoring force acting upon an
35 element of the electromechanical device.

56. The compensator according to Claim 55, wherein the circuitry for deriving $S(f(x(t)))$ implements the subtracted version represented by equation (36a).

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57. The compensator according to Claim 52, wherein the audio reproduction system includes a voice-coil, wherein the circuitry modifying the first input signal as a function of the second input signal derives $S(f(x(t)))$ from a ratio of a voice-coil restoring force to a motor factor of the voice-coil.

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58. The compensator according to Claim 57, wherein the circuitry for deriving $S(f(x(t)))$ implements the subtracted version represented by equation (36a).

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59. The compensator according to Claim 50, wherein the circuitry modifying the first input signal as a function of the second input signal derives $B(f(x(t)))$ as a function of a motor factor of the actuator.

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60. The compensator according to Claim 59, wherein the actuator motor factor is a drive force acting upon an element of the actuator for a fiducial value of an electric current driving the actuator.

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61. The compensator according to Claim 51, wherein the circuitry modifying the first input signal as a function of the second input signal derives $B(f(x(t)))$ as a function of a motor factor of the electromechanical device.

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62. The compensator according to Claim 61, wherein the motor factor of the electromechanical device is the electromagnetic drive force acting upon an element of the electromechanical device for a fiducial value of the electric current driving the electromechanical device.

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63. The compensator according to Claim 52, wherein the audio reproduction system includes a voice coil transducer, and further wherein the circuitry modifying the first input signal as a function of the second input signal derives $B(f(x(t)))$ as a function of a motor factor of the voice coil transducer.

64. A compensator for generating an actuator control signal, the compensator comprising circuitry for:

10 receiving a first time-dependent signal $w(t)$;
receiving a second, position-dependent signal $f(x(t))$,
where $x(t)$ is a measure of a position of a first portion of the actuator with respect to a second portion of the actuator; and

15 modifying the first input signal as a function of the second input signal by using a control law to produce the actuator control signal, $u(t)$, wherein the modifying implements the following control law:

20
$$u(t) = w(t)B(f(x(t))),$$

where $B(f(x(t)))$ represents a motor factor.

65. A compensator for generating a control signal for an electromechanical device, the compensator comprising circuitry for:

25 receiving a first time-dependent signal $w(t)$;
receiving a second, position-dependent signal $f(x(t))$,
where $x(t)$ is a measure of a position of a first portion of the electromechanical device with respect to a second portion of the electromechanical device; and

30 modifying the first input signal as a function of the second input signal by using a control law to produce the control signal, $u(t)$, wherein the modifying implements the following control law:

35

$$u(t) = w(t)B(f(x(t))),$$

where $B(f(x(t)))$ represents a motor factor.

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66. A compensator for generating a control signal for an audio reproduction system, the compensator comprising circuitry for:

receiving a first time-dependent signal $w(t)$;

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receiving a second, position-dependent signal $f(x(t))$, where $x(t)$ is a measure of a position of a first portion of the audio reproduction system with respect to a second portion of the audio reproduction system; and

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modifying the first input signal as a function of the second input signal by using a control law to produce the control signal, $u(t)$, wherein the modifying implements the following control law:

$$u(t) = w(t)B(f(x(t))),$$

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where $B(f(x(t)))$ represents a motor factor.

67. The compensator according to Claim 64, wherein the circuitry modifying the first input signal as a function of second input signal derives $B(f(x(t)))$ from a motor factor of the actuator.

68. The compensator according to Claim 67, wherein the actuator motor factor is a drive force acting upon an element of the actuator for a fiducial value of an electric current driving the actuator.

69. The compensator according to Claim 66, wherein the circuitry modifying the first input signal as a function of the second input signal derives $B(f(x(t)))$ from a motor factor of

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the electromechanical device.

70. The compensator according to Claim 69, wherein the motor factor of the electromechanical device is the
5 electromagnetic drive force acting upon an element of the electromechanical device for a fiducial value of the electric current driving the electromechanical device.

71. The compensator according to Claim 66, wherein the
10 audio reproduction system includes a voice coil transducer, and further wherein the circuitry modifying the first input signal as a function of the second input signal derives $B(f(x(t)))$ from a motor factor of the voice coil transducer.

15 72. A compensator for generating an actuator control signal, the compensator comprising circuitry for:

receiving a first time-dependent signal $w(t)$;

receiving a second, position-dependent signal $f(x(t))$,
where $x(t)$ is a measure of a position of a first portion of
20 the actuator with respect to a second portion of the actuator; and

modifying the first input signal as a function of the second input signal by using a control law to produce the actuator control signal, $u(t)$, wherein the modifying
25 implements the following control law:

$$u(t) = S(f(x(t))) + w(t),$$

where $S(f(x(t)))$ represents a restoring force.

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73. A compensator for generating a control signal for an electromechanical device, the compensator comprising circuitry for:

receiving a first time-dependent signal $w(t)$;

35 receiving a second, position-dependent signal $f(x(t))$,

where $x(t)$ is a measure of a position of a first portion of the electromechanical device with respect to a second portion of the electromechanical device; and

modifying the first input signal as a function of the second input signal by using a control law to produce the control signal, $u(t)$, wherein the modifying implements the following control law:

$$u(t) = S(f(x(t))) + w(t),$$

where $S(f(x(t)))$ represents a restoring force.

74. A compensator for generating a control signal for an audio reproduction system, the compensator comprising circuitry for:

receiving a first time-dependent signal $w(t)$;

receiving a second, position-dependent signal $f(x(t))$, where $x(t)$ is a measure of a position of a first portion of the audio reproduction system with respect to a second portion of the audio reproduction system; and

modifying the first input signal as a function of the second input signal by using a control law to produce the control signal, $u(t)$, wherein the modifying implements the following control law:

$$u(t) = S(f(x(t))) + w(t),$$

where $S(f(x(t)))$ represents a restoring force.

75. The compensator according to Claim 72, wherein the circuitry modifying the first input signal as a function of the second input signal derives the function $S(f(x(t)))$ at least in part from a position-dependent restoring force acting upon an element of the actuator.

76. The compensator according to Claim 75, wherein the circuitry modifying the first input signal as a function of the second input signal derives $S(f(x(t)))$ in accordance with the subtracted version of $S(f(x(t)))$ represented by equation (36a).

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77. The compensator according to Claim 73, wherein the circuitry modifying the first input signal as a function of the second input signal derives $S(f(x(t)))$ at least in part from a position-dependent restoring force acting upon an element of the electromechanical device.

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78. The compensator according to Claim 77, wherein the circuitry modify the first input signal as a function of the second input signal derives $S(f(x(t)))$ in accordance with the subtracted version of $S(f(x(t)))$ represented by equation (36a).

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79. The compensator according to Claim 74, wherein the audio reproduction system includes a voice coil and further wherein the circuitry modifying the first input signal as a function of the second input signal derives $S(f(x(t)))$ at least in part from a ratio of a voice-coil restoring force to a motor factor of the voice-coil.

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80. The compensator according to Claim 79, wherein the circuitry modifying the first input signal as a function of the second input signal derives $S(f(x(t)))$ in accordance with the subtracted version of $S(f(x(t)))$ as represented by equation (36a).

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81. A compensator for generating an actuator control signal, the compensator comprising circuitry for:

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receiving a first time-dependent signal, $w(t)$;

receiving a second, position-dependent signal,

$f(x(t))$, where $x(t)$ is a measure of a position of a first

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portion of the actuator with respect to a second portion of

the actuator; and

modifying the first input signal as a function of the position-dependent signal using a control law to produce the control signal, $u(t)$, where the modifying implements the following control law:

$$u(t) = w(t) + Z(f(x(t))) * d(w(t))/dt,$$

where $Z(f(x(t)))$ is a function $Z(\cdot)$ of $f(x(t))$, and $d(w(t))/dt$ is the time derivative of $w(t)$.

10 82. A compensator for generating a control signal for an electromechanical device, the compensator comprising circuitry for:

receiving a first time-dependent signal, $w(t)$;

receiving a second, position-dependent signal,

15 $f(x(t))$, where $x(t)$ is a measure of a position of a first portion of the electromechanical device with respect to a second portion of the electromechanical device; and

modifying the first input signal as a function of the position-dependent signal using a control law to produce the control signal, $u(t)$, where the modifying implements the following control law:

$$u(t) = w(t) + Z(f(x(t))) * d(w(t))/dt,$$

20 where $Z(f(x(t)))$ is a function $Z(\cdot)$ of $f(x(t))$, and $d(w(t))/dt$ is the time derivative of $w(t)$.

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83. A compensator for generating a control signal for a voice coil audio transducer, the compensator comprising circuitry for:

receiving a first time-dependent signal, $w(t)$;

30 receiving a second, position-dependent signal, $f(x(t))$, where $x(t)$ is a measure of a position of a first portion of the audio transducer with respect to a second portion of the audio transducer; and

modifying the first input signal as a function of the position-dependent signal using a control law to produce

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the control signal, $u(t)$, where the modifying implements the following control law:

$$u(t) = w(t) + Z(f(x(t))) * d(w(t))/dt,$$

where $Z(f(x(t)))$ is a function $Z(.)$ of $f(x(t))$, and
5 $d(w(t))/dt$ is the time derivative of $w(t)$.

84. The compensator according to Claim 81, wherein the circuitry modifying the first signal as a function of the position-dependent signal derives $Z(.)$ from an impedance of the
10 actuator.

85. The compensator according to Claim 82, wherein the circuitry modifying the first signal as a function of the position-dependent signal derives $Z(.)$ from an impedance of the
15 electromechanical device.

86. The compensator according to Claim 83, wherein the circuitry modifying the first signal as a function of the position-dependent signal derives $Z(.)$ from an impedance of a
20 transducer voice coil.

87. A compensator for generating a control signal for an actuator, the compensator comprising circuitry for:

receiving a first time-dependent signal, $w(t)$;

25 receiving a second, position-dependent signal, $f(x(t))$, where $x(t)$ is a measure of a position of a first portion of the actuator with respect to a second portion of the actuator; and

modifying the first input signal as a function of the position-dependent signal using a control law to produce the control signal, $u(t)$, where the modifying implements the following control law:

$$u(t) = w(t) + B1(f(x(t))) * d(F(f(x(t))))/dt,$$

where $B1(.)$ and $F(.)$ are functions of $f(x(t))$, and
35 $d(F(f(x(t))))/dt$ is a time derivative of the composite

function $F(f(x(t)))$.

88. A compensator for generating a control signal for an electromechanical device, the compensator comprising circuitry
5 for:

receiving a first time-dependent signal, $w(t)$;

receiving a second, position-dependent signal,
 $f(x(t))$, where $x(t)$ is a measure of a position of a first
10 portion of the electromechanical device with respect to a
second portion of the electromechanical device; and

modifying the first input signal as a function of the
position-dependent signal using a control law to produce
the control signal, $u(t)$, where the modifying implements
the following control law:

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$$u(t) = w(t) + B1(f(x(t))) * d(F(f(x(t))))/dt,$$

where $B1(.)$ and $F(.)$ are functions of $f(x(t))$, and
 $d(F(f(x(t))))/dt$ is the time derivative of the composite
function $F(f(x(t)))$.

20 89. A compensator for generating a control signal for a
voice coil audio transducer, the compensator comprising
circuitry for:

receiving a first time-dependent signal, $w(t)$;

receiving a second, position-dependent signal,
25 $f(x(t))$, where $x(t)$ is a measure of a position of a first
portion of the audio transducer with respect to a second
portion of the audio transducer; and

modifying the first input signal as a function of the
position-dependent signal using a control law to produce
30 the control signal, $u(t)$, where the modifying implements
the following control law:

$$u(t) = w(t) + B1(f(x(t))) * d(F(f(x(t))))/dt,$$

where $B1(.)$ and $F(.)$ are functions of $f(x(t))$, and
 $d(F(f(x(t))))/dt$ is the time derivative of the composite
35 function $F(f(x(t)))$.

90. The compensator according to Claim 87, wherein the circuitry modifying the first signal as a function of the position-dependent signal derives $B1(f(x(t)))$ from a motor factor of the actuator, and further wherein $F(f(x(t)))$ is an estimate of a relative position of a first portion of the actuator with respect to a second portion of the actuator, and where the estimate is derived from a position-indicator actuator generalized coordinate $f(x(t))$.

91. The compensator according to Claim 87, wherein the function $B1(.)$ is comprised of a first portion derived from a non-linear motor factor of the actuator minus a second portion which represents an adjustable, approximately linear damping.

92. The compensator according to Claim 88, wherein the circuitry modifying the first signal as a function of the position-dependent signal derives $B1(f(x(t)))$ from a motor factor of the electromechanical device; wherein $F(f(x(t)))$ is an estimate of a relative position of a first portion of the electromechanical device with respect to a second portion of the electromechanical device derived from a position-indicator generalized coordinate $f(x(t))$ of the electromechanical device; and further wherein $x(t)$ is the relative position.

93. The compensator according to Claim 88, wherein the function $B1(.)$ is comprised of a first portion derived from a non-linear motor factor of the actuator minus a second portion which represents an adjustable, approximately linear damping.

94. The compensator according to Claim 89, wherein the voice coil audio transducer comprises a voice coil and an associated diaphragm, wherein the circuitry modifying the first signal as a function of the position-dependent signal derives $B1(f(x(t)))$ from a motor factor of the voice coil audio

transducer and $F(f(x(t)))$ is an estimate of position of the coil and associated diaphragm derived from a position-indicator generalized coordinate $f(x(t))$ of the audio transducer, and wherein $x(t)$ is the position of the coil and associated
5 diaphragm with respect to another portion of the transducer.

95. The compensator according to claim 89, where the function $Bl(.)$ comprises a first portion derived from a non-linear motor factor of the actuator minus a second portion which
10 represents an adjustable, approximately linear damping.

96. The compensator according to claim 95, wherein the circuitry modifying the first signal as a function of the position-dependent signal derives the second portion from the
15 equation:

$$p \cdot BL(0) \cdot BL(0) / BL(f(x(t))),$$

where p is an adjustable constant;

where $BL(0)$ is a motor factor of the voice coil and associated diaphragm when no drive signal is applied to the
20 voice coil; and

$BL(f(x(t)))$ is a position-dependent nonlinear motor factor.

97. The compensator according to claim 83, wherein the
25 first time-dependent signal $w(t)$ is an audio program transducer input.

98. The compensator according to claim 89, wherein the
30 first time-dependent signal $w(t)$ is an audio program transducer input.